THE INVENTION CLAIMED IS:

1. A method of mobile device control comprising:

moving a surrogate under wireless control by a user; and

autonomously moving the surrogate to regain wireless control when the wireless control is lost.

2. The method as claimed in claim 1 additionally comprising:

autonomously moving the surrogate along a previously determined route.

3. The method as claimed in claim 1 wherein:

autonomously moving the surrogate to regain wireless control occurs after a period of time.

4. The method as claimed in claim 1 wherein:

autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

5. The method as claimed in claim 1 wherein:

moving the surrogate under wireless control includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

6. The method as claimed in claim 1 wherein:

autonomously moving the surrogate uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement.

7. A method of mobile telepresencing comprising:

moving a surrogate under real-time wireless control by a user; and

autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time.

8. The method as claimed in claim 7 additionally comprising:

autonomously moving the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

9. The method as claimed in claim 7 wherein:

losing wireless control includes degradation of the control to a threshold level;

autonomously moving the surrogate to regain wireless control occurs after a period of time.

10. The method as claimed in claim 7 wherein:

autonomously moving the surrogate includes;

backtracking while measuring distance and avoiding collisions by the surrogate;

stopping the surrogate for an obstacle; and

resuming backtracking after removal of the obstacle.

11. The method as claimed in claim 7 wherein:

moving the surrogate under wireless control includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

12. The method as claimed in claim 7 wherein:

autonomously moving the surrogate to backtrack uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof;

autonomously moving the surrogate to backtrack uses a slower speed than forward speed; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

13. A mobile device control system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system on the surrogate for moving the surrogate to regain wireless control when the wireless control is lost.

14. The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate along a previously determined route.

15. The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after a period of time.

16. The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

17. The system as claimed in claim 13 wherein:

the computer/transceiver system includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

18. The system as claimed in claim 13 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof; and

the computer/transceiver system calculates waypoints back along a forward movement path for backtracking movement.

19. A mobile telepresencing comprising:

a surrogate movable under real-time wireless control by a user; and

a computer/transceiver system for autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time.

20. The system as claimed in claim 19 additionally comprising:

the computer/transceiver system for autonomously moving the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

21. The system as claimed in claim 19 wherein:

the computer/transceiver system for determining degradation of the wireless control to a threshold level;

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after a period of time.

22. The system as claimed in claim 19 wherein:

the computer/transceiver system for autonomously moving the surrogate includes;

backtracking means for measuring distance and avoiding collisions by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for resuming backtracking after removal of the obstacle.

23. The system as claimed in claim 19 wherein:

the computer/transceiver system includes means for logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

24. The system as claimed in claim 19 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof for backtracking;

the computer/transceiver system provides a slower speed than forward speed for backtracking by the surrogate; and

the computer/transceiver system uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.